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COMMAND\$3	0
COMMAND	545336
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((L2 OR L3) AND ((HAPTIC ADJ COMMAND\$3) AND (ENABL\$3 ADJ5 DISABL\$3))).PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD.	2

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<u>L17</u>	(l2 or l3) and ((haptic adj command\$3) and (enabl\$3 adj5 disabl\$3))	2 <u>L17</u>
<u>L16</u>	(l2 or l3) and ((haptic adj command\$3) and (enabl\$3 adj3 disabl\$3))	2 <u>L16</u>
<u>L15</u>	(l2 or l3) and ((haptic adj command\$3) and (part adj3 data adj5 manag\$5) and (enabl\$3 adj3 disabl\$3))	2 <u>L15</u>
<u>L14</u>	(l2 or l3) and ((haptic adj command\$3) and (part adj3 data adj5 manag\$5))	2 <u>L14</u>
<u>L13</u>	(l2 or l3) and ((haptic adj command\$3) and (part adj3 data adj5 table))	2 <u>L13</u>
<u>L12</u>	(l2 or l3) and ((haptic adj command\$3) and (part adj3 data))	5 <u>L12</u>
<u>L11</u>	(l2 or l3) and ((haptic adj commander))	2 <u>L11</u>
<u>L10</u>	(l2 or l3) and ((haptic adj commander) and (part adj3 data))	2 <u>L10</u>
<u>L9</u>	(l2 or l3) and ((haptic adj commander) and (data adj3 table))	2 <u>L9</u>
<i>DB=EPAB; PLUR=YES; OP=ADJ</i>		
<u>L8</u>	EP-1471410-A2.did.	0 <u>L8</u>
<i>DB=PGPB; PLUR=YES; OP=ADJ</i>		
<u>L7</u>	US-20040201605-A1.did.	1 <u>L7</u>
<i>DB=JPAB; PLUR=YES; OP=ADJ</i>		
<u>L6</u>	JP-2004319173-A.did.	1 <u>L6</u>
<i>DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ</i>		
<u>L5</u>	(l2 or l3) and ((haptic adj commander) and (data adj3 manag\$5))	2 <u>L5</u>
<u>L4</u>	L3 and L2	1 <u>L4</u>
<u>L3</u>	(force adj feedback) and (input\$4 adj device) and (position\$3 adj3 detect\$3 adj5 state)	5 <u>L3</u>
<u>L2</u>	(force adj feedback) and (input\$4 adj device) and (haptic adj3 command\$3)	38 <u>L2</u>
<u>L1</u>	(force adj feedback) and (input\$4 adj device) and (position\$3 adj3 detect\$3 adj5 state) and (haptic adj3 command\$3)	1 <u>L1</u>

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| <u>#3</u> | (force feedback and input device<IN>metadata) |
| <u>#4</u> | (force feedback and input device<IN>metadata) |
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| <u>#6</u> | ((force feedback input device haptic commander)<in>metadata) |
| <u>#7</u> | (matsumoto k.<in>au) |
| <u>#8</u> | ((matsumoto k.<in>au)<AND>(matsumoto k.<in>au) and (force feedback) and (input device)) |
| <u>#9</u> | ((matsumoto k.<in>au)<AND>(matsumoto k.<in>au) and (force feedback) and (input device)) |
| <u>#10</u> | (((((matsumoto k.<in>au)<and>(matsumoto k.<in>au) and (force feedback) and (input device)))<AND>(((matsumoto k.<in>au)<and>(matsumoto k.<in>au) and (force feedback) and (input device)) and (haptic commander)) |
| <u>#11</u> | ((matsumoto k.<in>au)<AND>(matsumoto k.<in>au) and (force feedback) and (input device)) |
| <u>#12</u> | (matsumoto k.<in>au) |
| <u>#13</u> | (matsumoto k.<in>au) |
| <u>#14</u> | ((matsumoto k.<in>au)<AND>(haptic commander<in>metadata)) |
| <u>#15</u> | (matsumoto k.<in>au) |
| <u>#16</u> | (matsumoto k.<in>au) |
| <u>#17</u> | ((matsumoto k.<in>au)<AND>(force feedback<in>metadata)) |

- #18 (((matsumoto k.<in>au))<AND>(force feedback<in>metadata))
- #19 (((matsumoto k.<in>au))<AND>(force feedback<in>metadata))
- #20 (((matsumoto k.<in>au))<AND>(force feedback<in>metadata))
- #21 (matsumoto k.<in>au)
- #22 (hayasaki s.<in>au)



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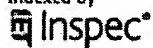
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 Digital Object Identifier 10.1109/100.894033
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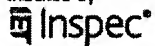
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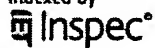
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 Volume 7, Issue 4, Dec. 2000 Page(s):50 - 63
 Digital Object Identifier 10.1109/100.894033
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- ☐ 2. **Force reflection for time-delayed teleoperation of Space robots**
 Penin, L.F.; Matsumoto, K.; Wakabayashi, S.;
[Robotics and Automation, 2000. Proceedings. ICRA '00. IEEE International Co](#)
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